

Figure 1.

PRIOR ART

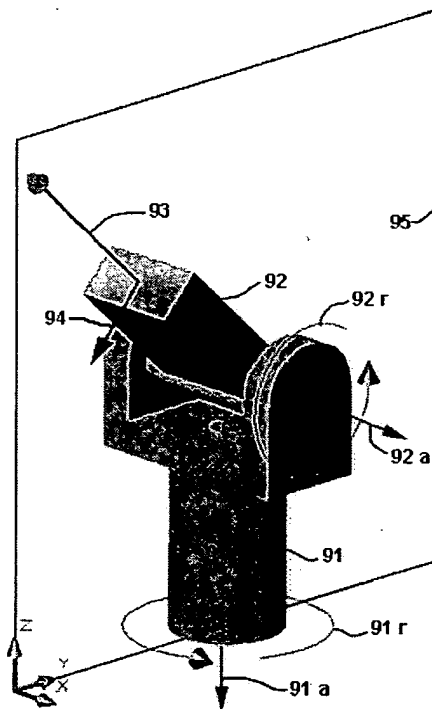


Figure 2

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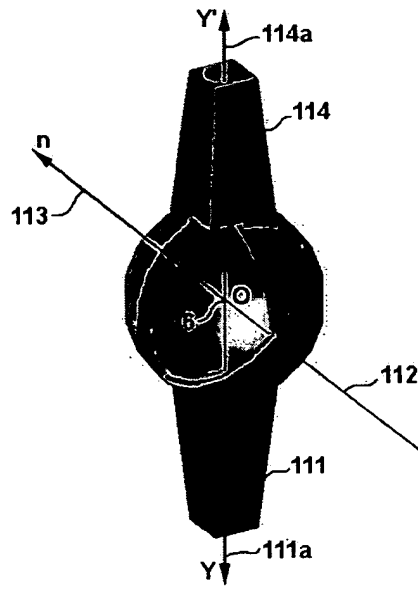


Figure 3a

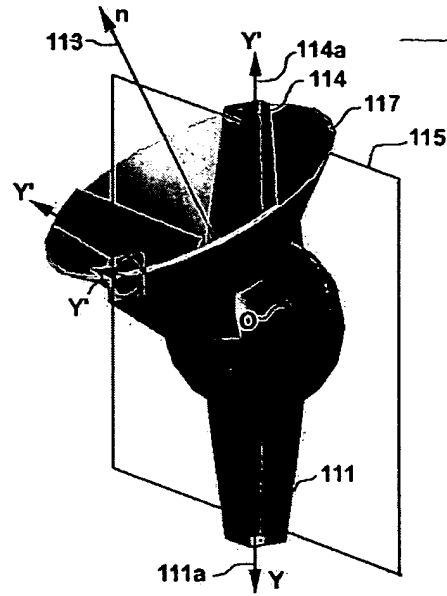


Figure 3b

PRIOR ART

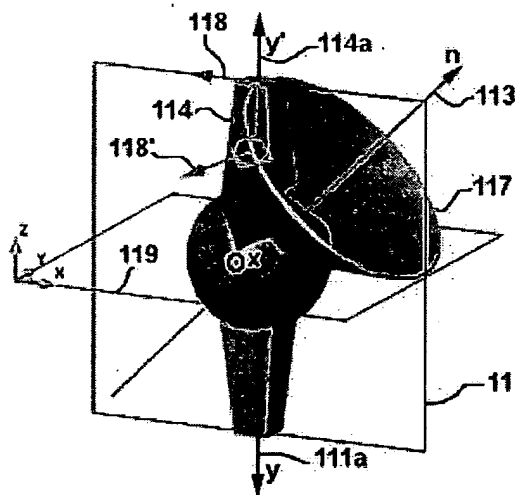


Figure 4a

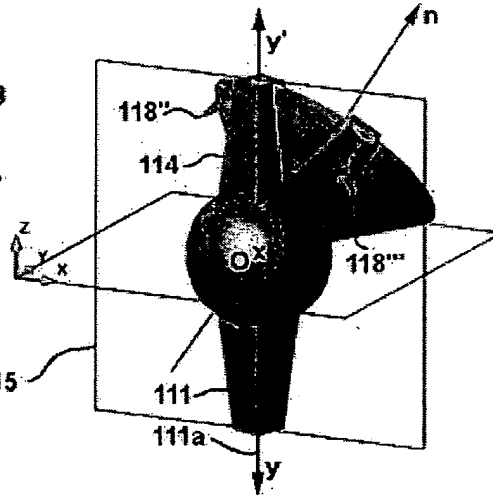


Figure 4b

PRIOR ART

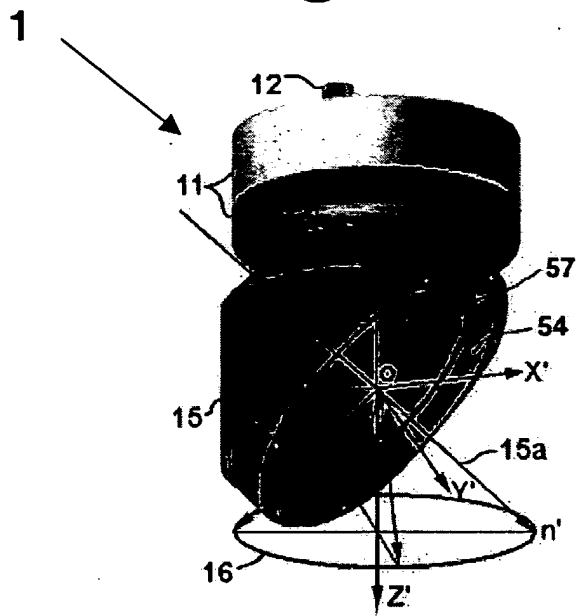


Figure 5a

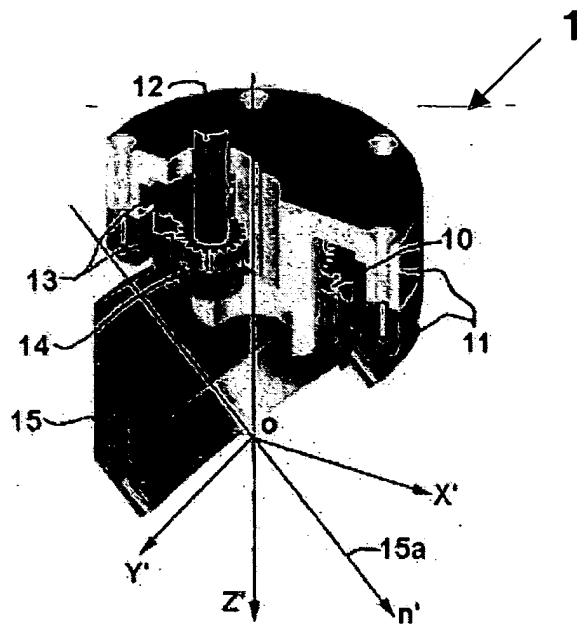


Figure 5b

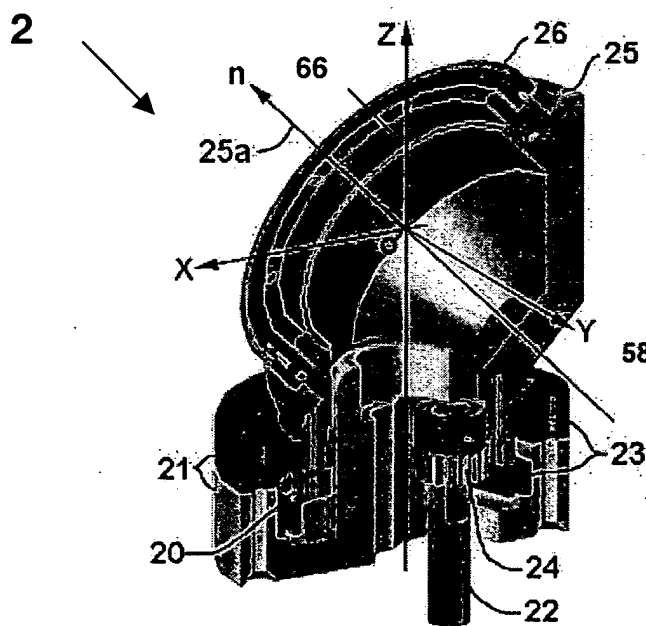


Figure 6a

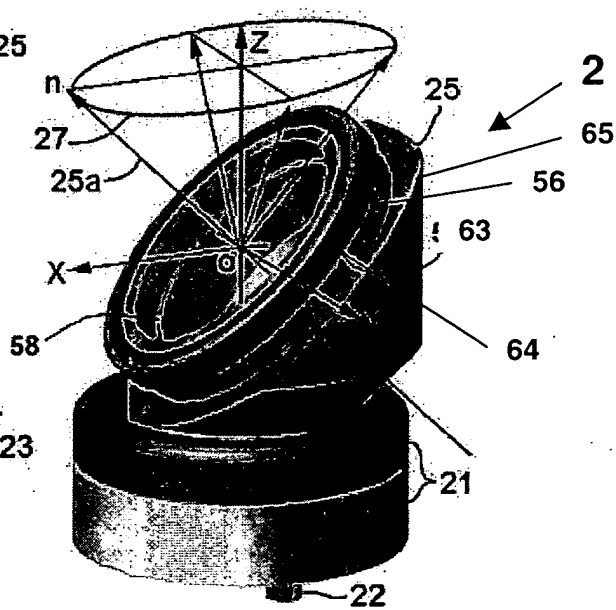


Figure 6b

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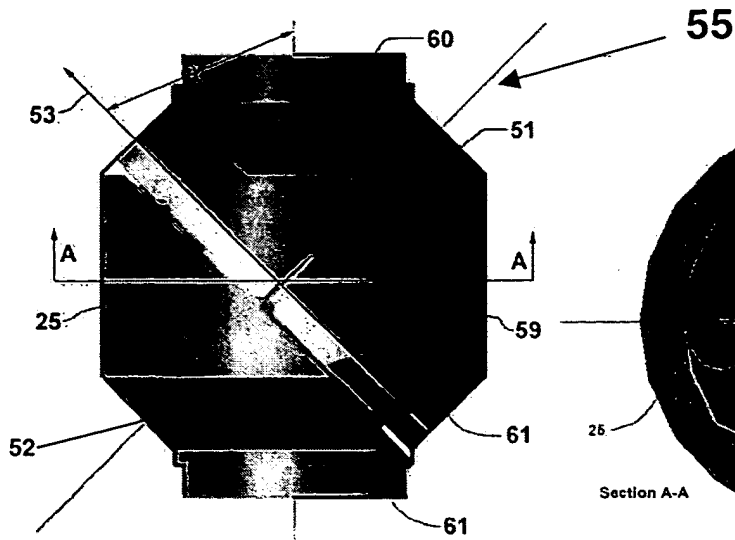


Figure 7a

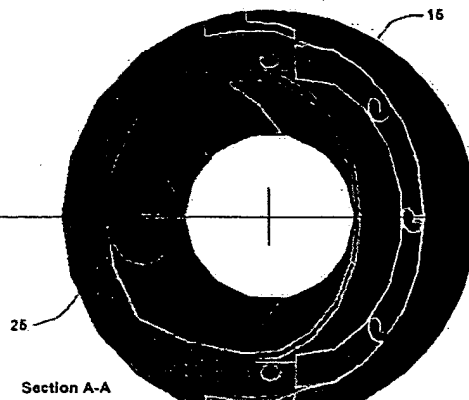


Figure 7b

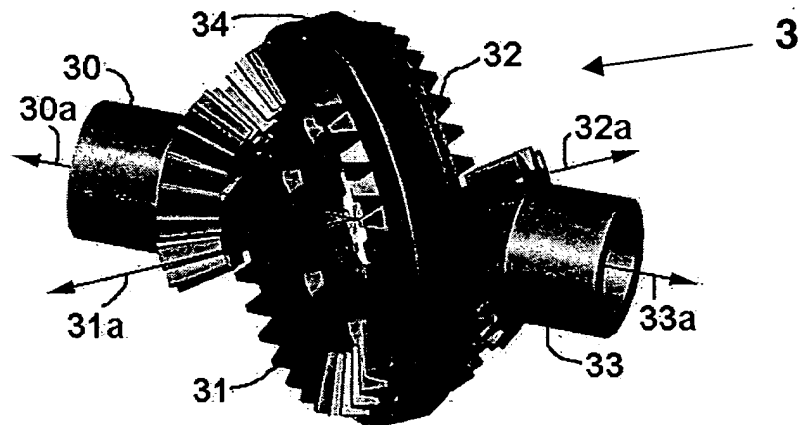


Figure 8

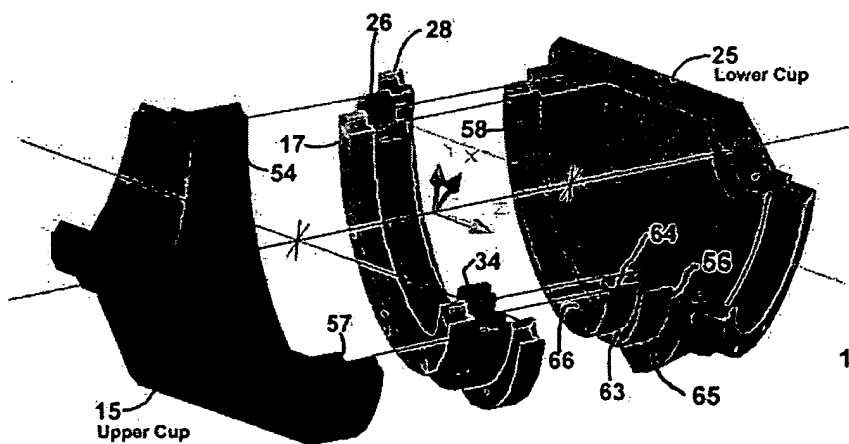


Figure 9a

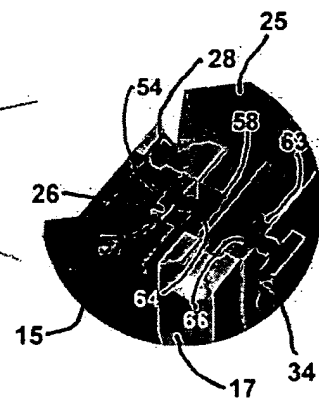


Figure 9b

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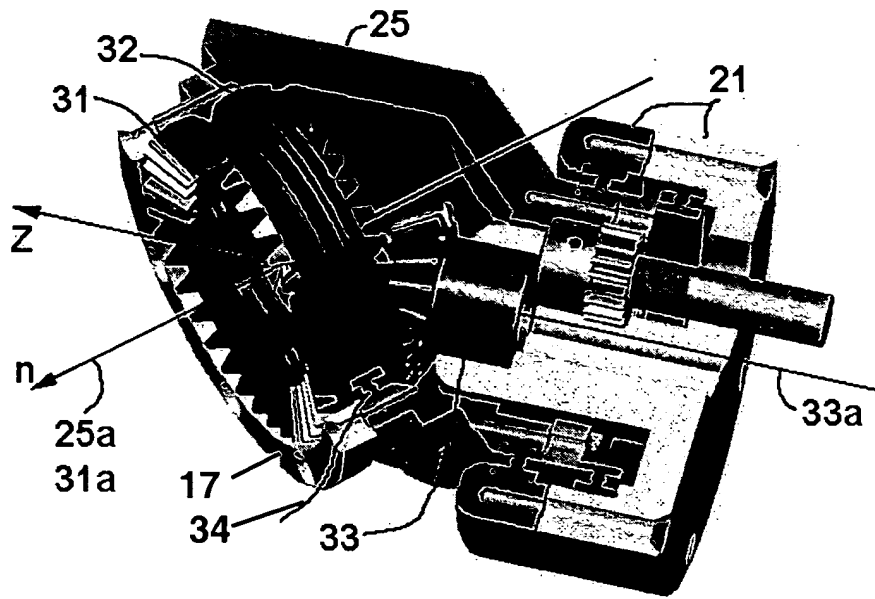


Figure 10

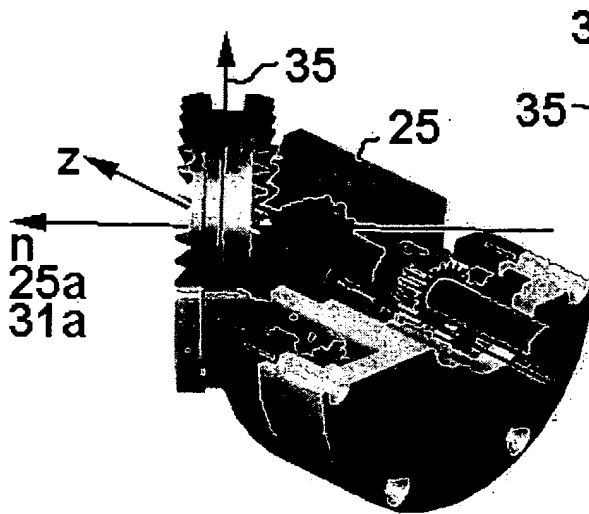


Figure 11a

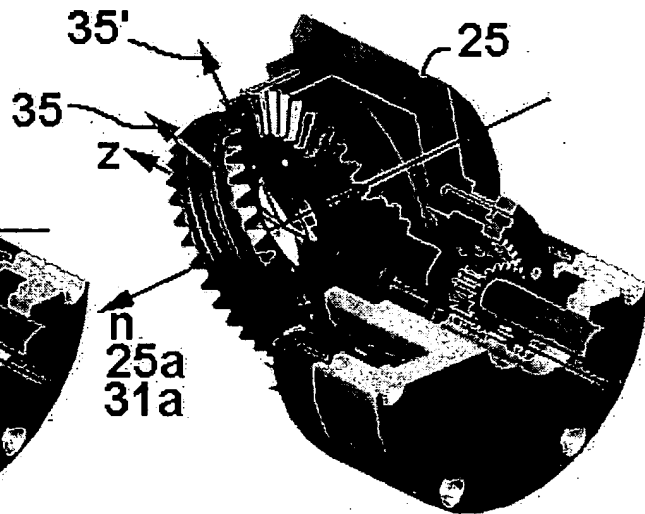


Figure 11b

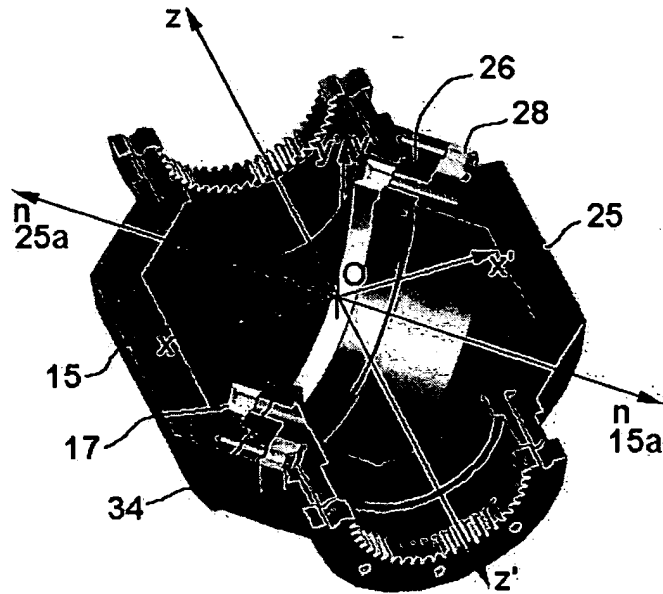


Figure 12

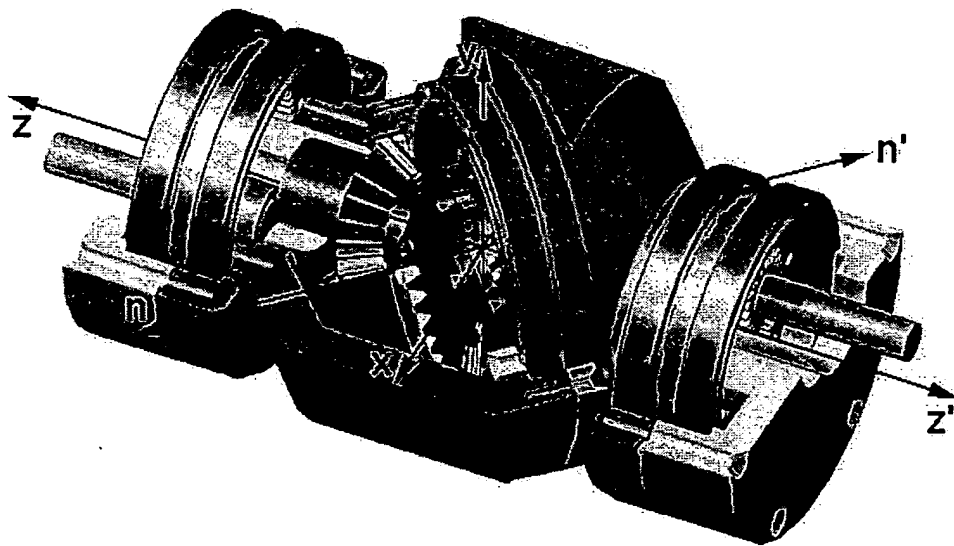


Figure 13

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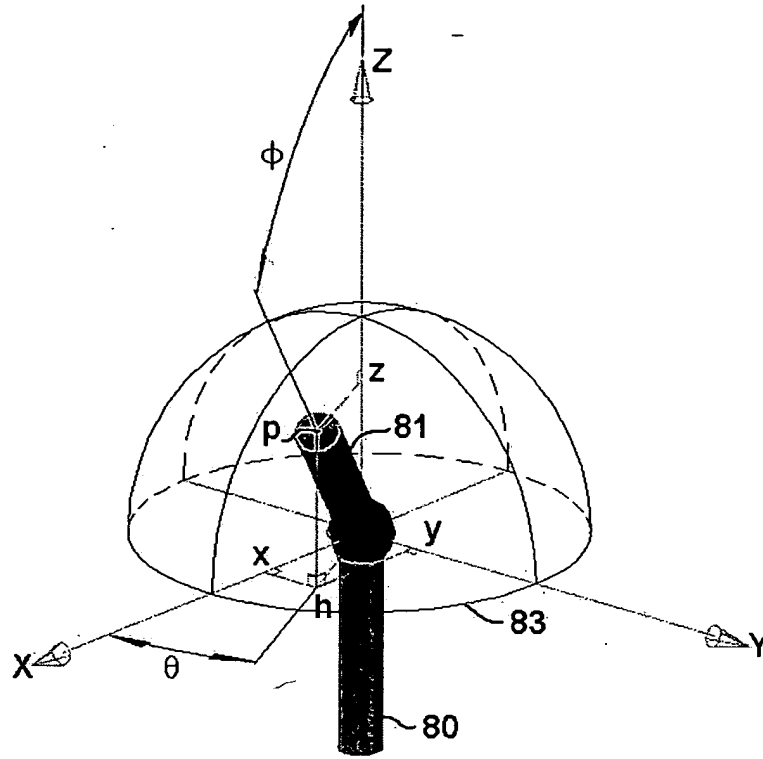


Figure 14

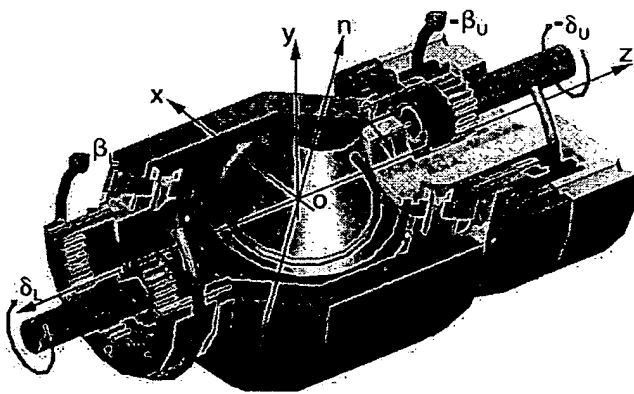


Figure 15a

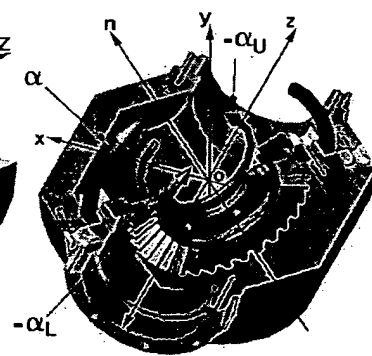


Figure 15b

A 3D perspective diagram of a mechanical assembly, possibly a valve or a pump component, positioned within a 3D coordinate system. The axes are labeled Z_0 (vertical), X_0 (horizontal to the left), and X_1 (diagonal down-left). A secondary axis Z_1 is also shown, pointing towards the top-left. The assembly is a complex, curved structure with various internal and external features, including a central vertical shaft or rod. Dashed lines indicate the projection of the assembly onto the coordinate planes.

Figure 18b

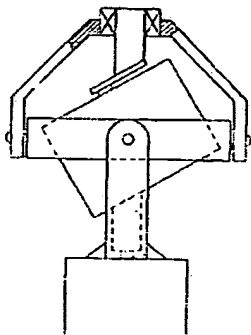


Figure 19a

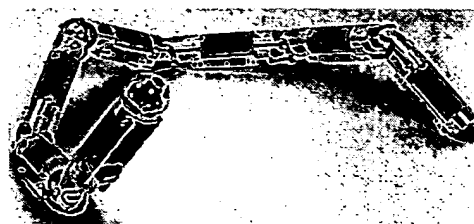


Figure 19b

PRIOR ART

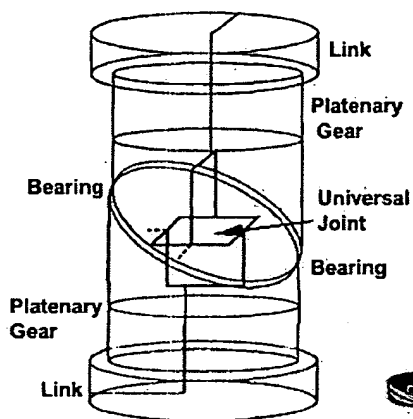


Figure 20a

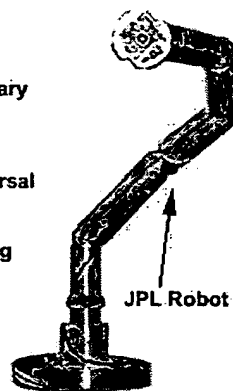


Figure 20b

PRIOR ART

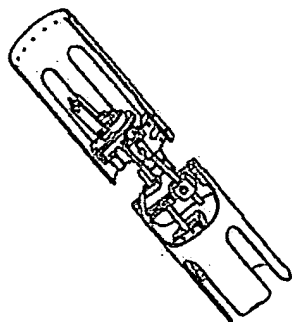


Figure 21a

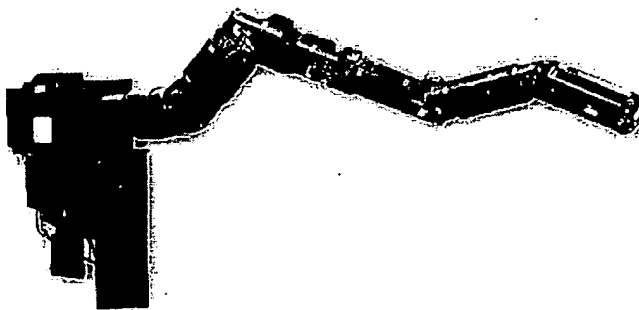


Figure 21b

PRIOR ART

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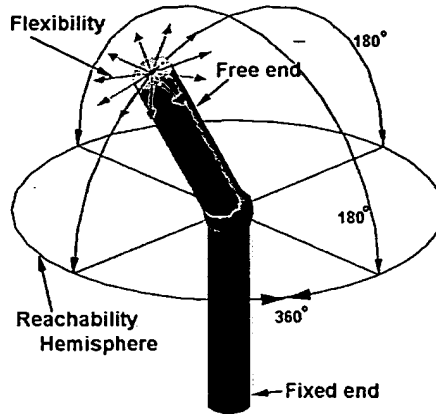


Figure 22

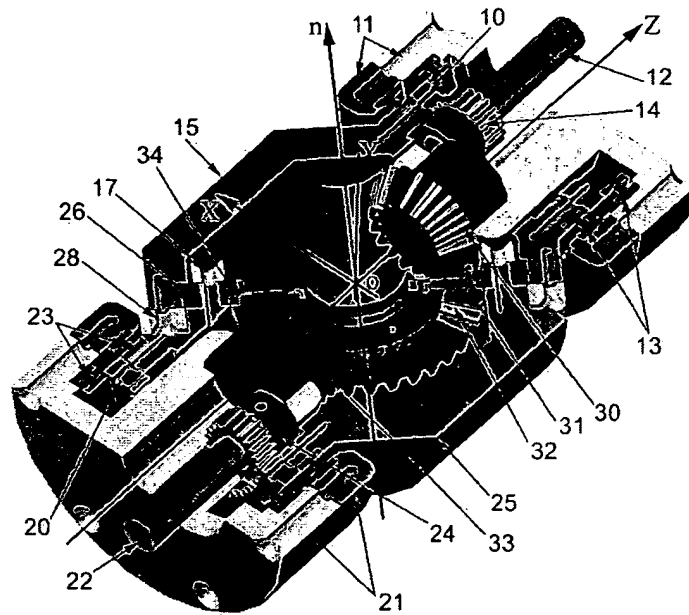


Figure 23

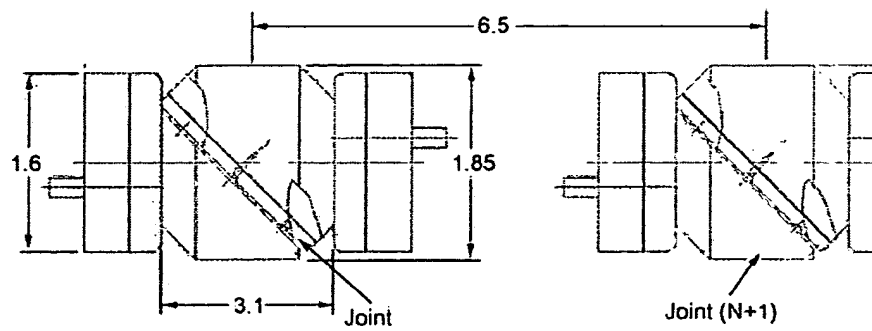


Figure 24

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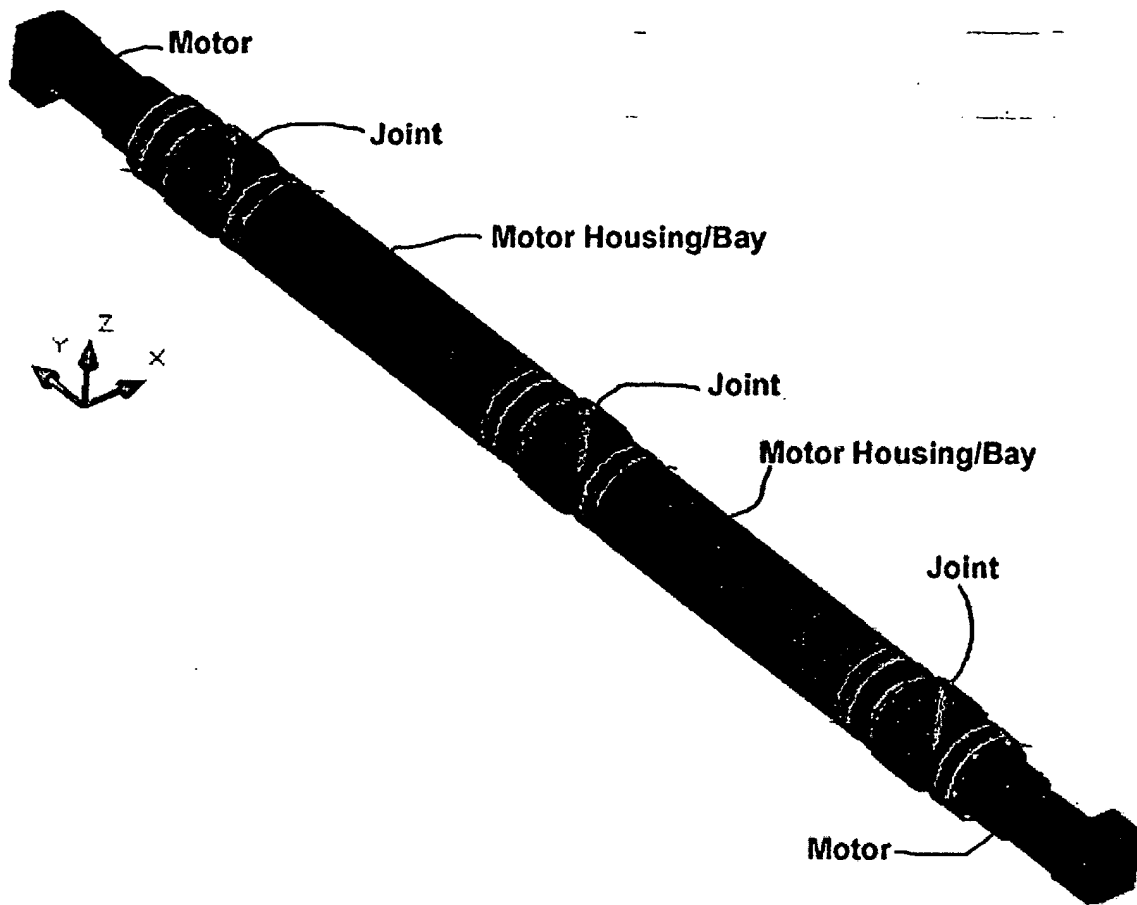


Figure 25.

Figure 25 shows part of a snake robot wherein motor housings / bays are connected together with joints of the present invention.

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